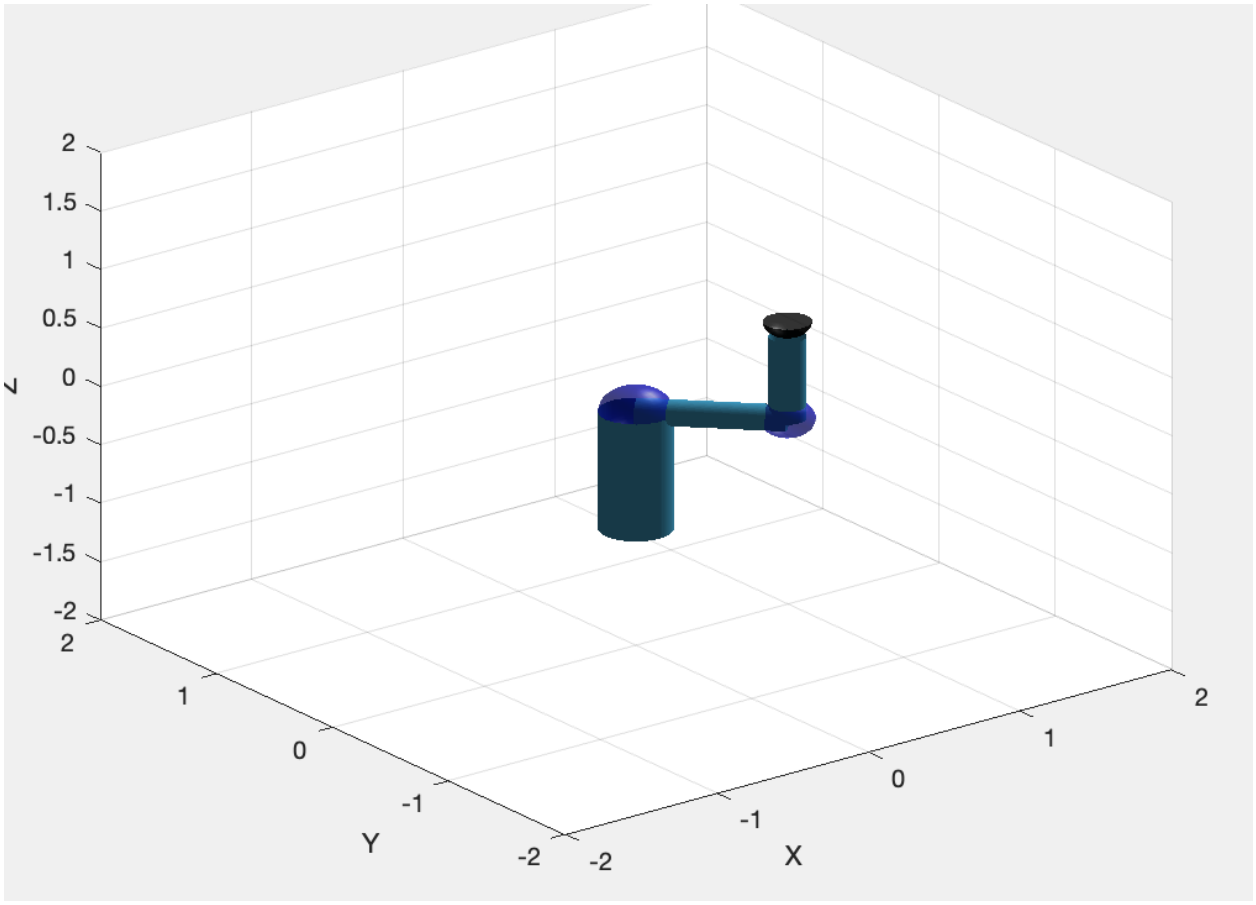
Elbow is at pi/2 (orientation of the base joint does not matter)

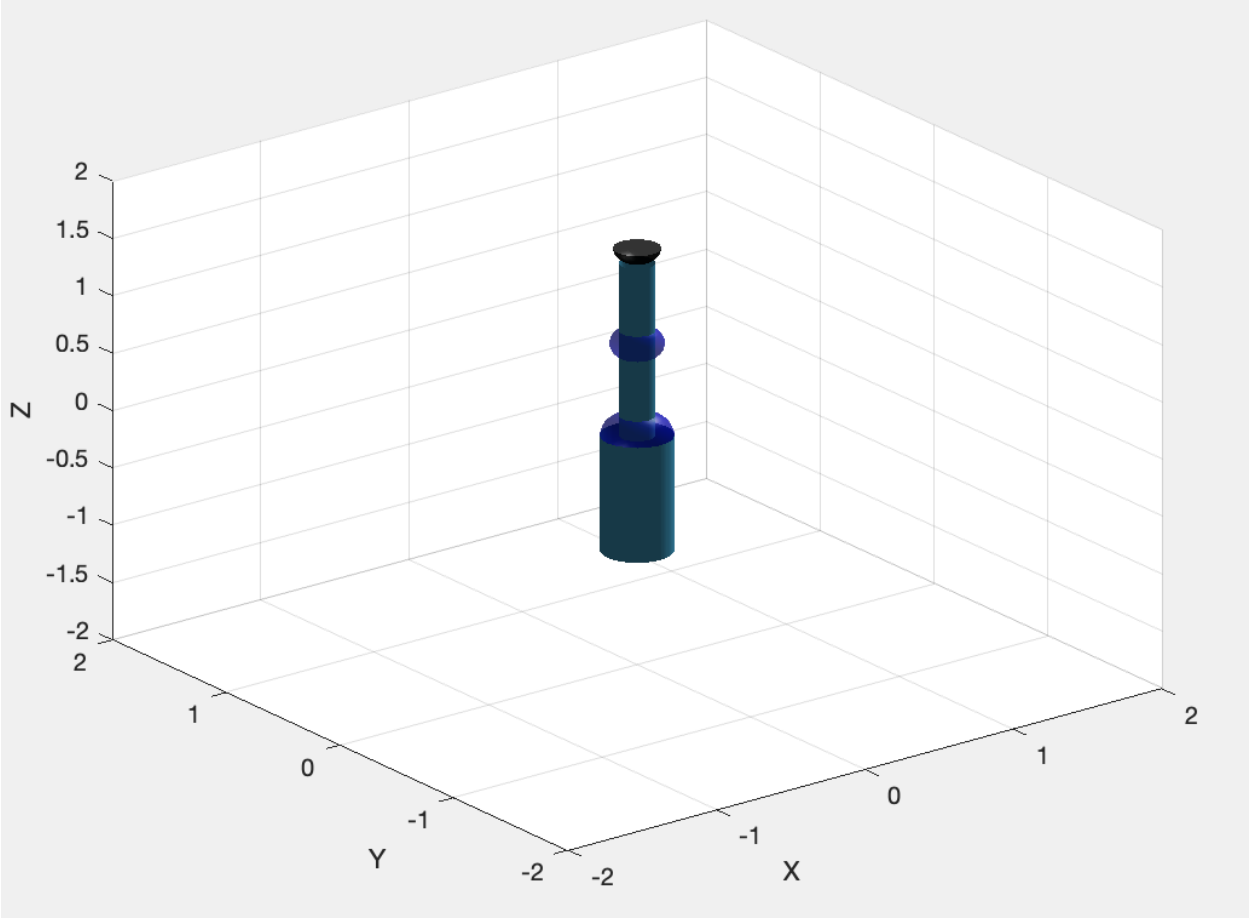


Rotational Angle: [0,pi/2,-pi/4])

```
Jacobian matrix:
   -0.4950   -0.4950    0.5657
    0.4950    0.4950    0.5657
    0.8000    0.0000         0

Condition number:
    2.4915
```

The whole arm is fully stretched upward in a straight line



Angle: [pi/2,pi,pi/2]

```
Jacobian matrix:
   -0.0000    0.0000    0.0000
   -0.1000    0.7000   -0.0000
   -0.0000   -0.0000         0

Condition number:
   8.8830e+15
```

This configuration(The whole arm is fully stretched upward in a straight line**)**
would give a singular matrix

```
Jacobian matrix:
   -0.0000   -0.0000    0.0000
    0.0000    0.0000    0.1000
   -0.1000    0.7000         0

Condition number:
   7.2639e+15
```

Angle [pi,pi,pi] will also give a singular Jacobian matrix